

IN THE CLAIMS:

Please amend claim 1 as follows.

1. (Currently Amended) A leg type mobile robot comprising:

~~an-a~~ body;

legs each connected to the body via a first joint; and

~~feet-feet,~~ each connected to an end part of the leg via a second joint, wherein the
each foot includes

at least one foot portion, which has a ground area to be grounded on a floor
surface at the bottom thereof, and

a floor reaction force detector for detecting floor reaction force acting from
a floor surface through the foot portion, and wherein

~~the-a~~ center (Pc) of the second joint is offset against ~~the-a~~ position Pa in a plane
view,

the position Pa is the position where the distance to the remotest point of at least
one ground area becomes minimum, and

~~the-a~~ center (Pb) of the floor reaction force detector is provided so that the center
Pb is in the vicinity of the position Pa than the center Pc of the ankle joint in a plane
view.

2. (Original) A leg type mobile robot according to claim 1, wherein

the center (Pb) of the floor reaction force detector is offset to a rear direction with respect to the position (Pa).

3. (Original) A leg type mobile robot according to claim 2, wherein the center (Pb) of the floor reaction force detector is positioned on a line segment connecting the position (Pa) and the center (Pc) of the second joint.

4. (Original) A leg type mobile robot according to claim 1, wherein the center (Pb) of the floor reaction force detector is offset to a rear direction in a center side of the leg type mobile robot with respect to the position (Pa).

5. (Original) A leg type mobile robot according to claim 4, wherein the center (Pb) of the floor reaction force detector is located on the perpendicular taken down from the center (Pc) of the second joint to the line segment extended from the position (Pa) to a rear direction.

6. (Original) A leg type mobile robot according to claim 4, wherein the center (Pb) of the floor reaction force detector is located on the perpendicular taken down from the center (Pc) of the second joint to the line segment extended from the position (Pa) to a center of the leg type mobile robot.

7. (Original) A leg type mobile robot according to claim 4, wherein
the center (Pb) of the floor reaction force detector is positioned on a line segment
connecting the position (Pa) and the center (Pc) of the second joint.